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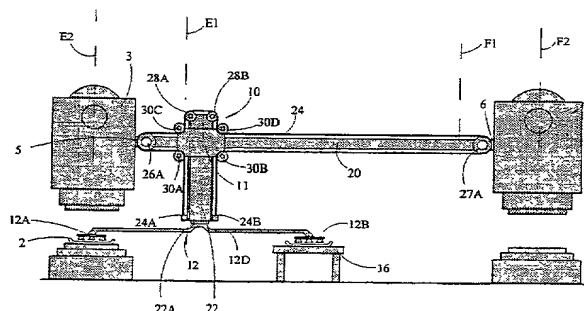
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(54) Title: **ROBOT UNIT**



(57) Abstract: The present invention relates to a method for rapid transfer of a work object in both the horizontal and vertical directions using a robot unit (10) having a gripping mechanism (12) preferably from one workstation (3) to another (4), the work piece (2) weighing between one kilo and forty kilos and the transfer in the horizontal direction being at least one metre but less than ten metres and at least partially being effected along an essentially horizontally extending beam unit (20), and the grippig mechanism (12) being arranged in such a way that, at least in one end situation (E1) along the beam (20), it can collect and/or deliver a work object (2) in a position (E2) situated beyond the end situation (E1) along the said horizontal beam (20), which robot unit is controlled by means of a control unit (50) and is driven by means of a belt member (24) and at least two motors (26, 27) comprising rotor units connected to drive wheels (26A, 27A) for the said belt member (24), the said motors (26, 27) being immovably arranged in relation to the said workstations (3, 4) and the transfer of the work object (2) being effected without displacement of either of the said two motors (26, 27), characterized in that the whole of the transfer is executed along one and the same beam unit (20), in that the said belt member (24) is constituted by a single continuous drive belt (24), which, at the same time, is connected to and driven by the said drive wheels (26A, 27A), and by the displacement of the work object being guided along a pre-programmed path by means of a control computer (51) in the control unit (50) through the continuous control and registration of the situation of each of the rotors forming part of the said motors (26, 27).